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Deep Neural Network Hardware Deployment Optimization via Advanced Active Learning

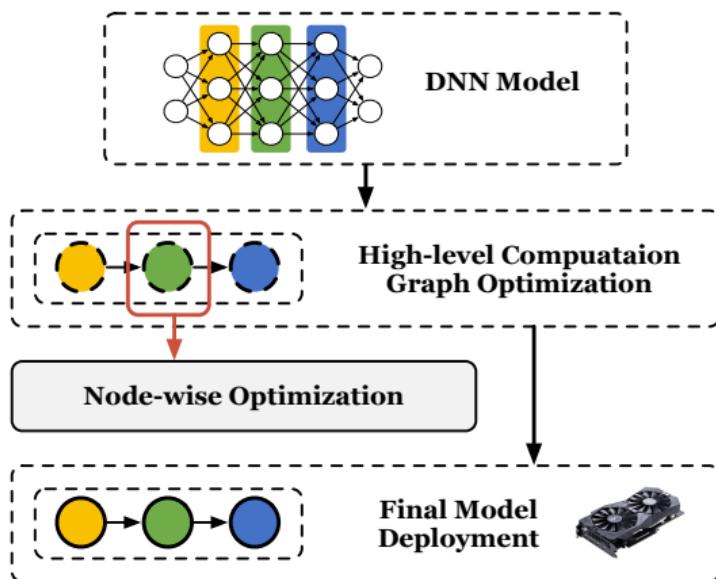
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Background

Hardware deployment of deep neural networks



- ▶ General deployment framework.
- ▶ Support various hardware platforms and DNN models.
- ▶ A DNN model is represented as a graph.
- ▶ Layer-wise (node-wise) optimization, to determine the deployment configuration for each layer.
- ▶ The final model deployment configuration is the combination of the layers.

Background – Some Definitions

Deployment configuration

All of the deployment settings (e.g., thread binding, tensor decomposition, etc.) to be determined are encoded as a feature vector, denoted as x .

GFLOPS

Giga floating operations per second (GFLOPS) measures the number of floating-point operations conducted by the hardware per second.

Latency

Latency computes end-to-end model inference time and intuitively reflects the performance of model deployment.

Objective

Find the optimal x , which has the best deployment performance, from the design space \mathcal{D} .

Background – Traditional active learning optimization

Initialization

- ▶ Randomly sample some configurations from the design space.
- ▶ Initialize an evaluation model (e.g., XGBoost).

Iterative optimization

- ▶ Iteratively select a configuration according to the evaluation model and searching strategy
- ▶ Compile and deploy the configuration.
- ▶ Update the evaluation model.
- ▶ Stop until convergence.

Background

Current status

- ▶ Usually more than millions of candidate configurations in the design space.
- ▶ Slow compilation and deployment processes.

Unsolved problems

- ▶ **Initialization** with underabundant information
- ▶ **Un-scalability** of the optimization process
- ▶ **Inaccuracy** of evaluation functions

Our Solution

Targets

- ▶ Improve data **diversity**.
- ▶ Improve model **scalability**.
- ▶ Improve model **accuracy**.

Proposed methods

- ▶ Batch Transductive Experimental Design
- ▶ Bootstrap-guided Adaptive Optimization

Maximize the intra-set diversity

$$x = \arg \max_{v \in \mathcal{V}} \frac{\|K_v\|^2}{k(v, v) + \mu}$$

- ▶ K : Euclidean distance matrix
- ▶ K_v is v 's corresponding column in K
- ▶ $k(v, v)$ is v 's diagonal entry in K , μ is a coefficient
- ▶ Iteratively select the configuration point which has the largest distance to other configurations
- ▶ The selected points are the **initialization set** for the evaluation model

Initialization – Batch TED

Batch method

- ▶ Computing distance matrix is very slow, even impossible.
- ▶ Sample a batch of sets from the design space and compute the distance matrix for each set.

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Algorithm 2 Batch Transductive Experimental Design –
BTED($\mathcal{V}, \mu, M, m, B$)

Require: ($\mathcal{V}, \mu, M, m, B$), where \mathcal{V} is the un-sampled configuration set, μ is the normalization coefficient, B is the batch size, M is the number of randomly sampled points and m is the number of points to be sampled as the initial set.

Ensure: Newly sampled configuration set \mathcal{X} .

- 1: **for** $b = 1 \rightarrow B$ **do**
- 2: Randomly sample a set \mathcal{V}_b from \mathcal{V} , with $|\mathcal{V}_b| = M$;
- 3: $\tilde{\mathcal{X}}_b \leftarrow \text{TED}(\mathcal{V}_b, \mu, m)$;
- 4: **end for**
- 5: Temporal union set $\tilde{\mathcal{X}}_U = \tilde{\mathcal{X}}_1 \cup \tilde{\mathcal{X}}_2 \cup \dots \cup \tilde{\mathcal{X}}_B$;
- 6: $\mathcal{X} \leftarrow \text{TED}(\tilde{\mathcal{X}}_U, \mu, m)$; **return** Newly sampled configuration set \mathcal{X} ;

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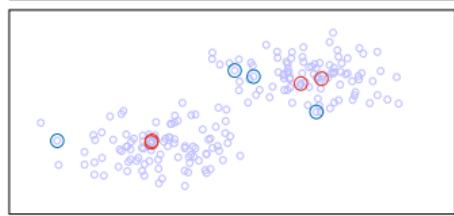
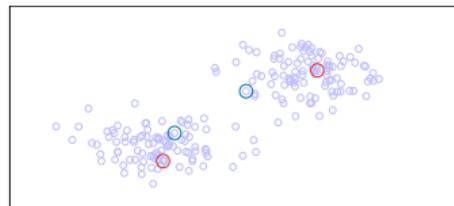
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▶ Example

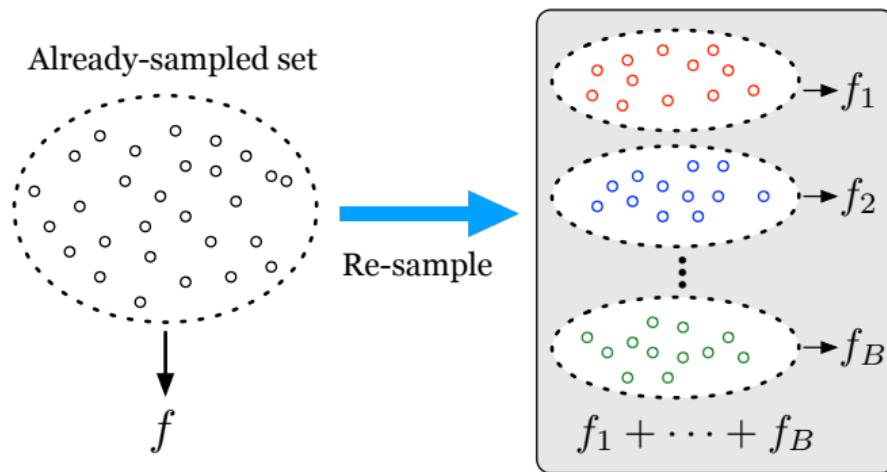
◦ Design Space ◦ BTED ◦ Random



Iterative Opt. – Bootstrap-guided Adaptive Opt. (BAO)

Bootstrap re-sampling

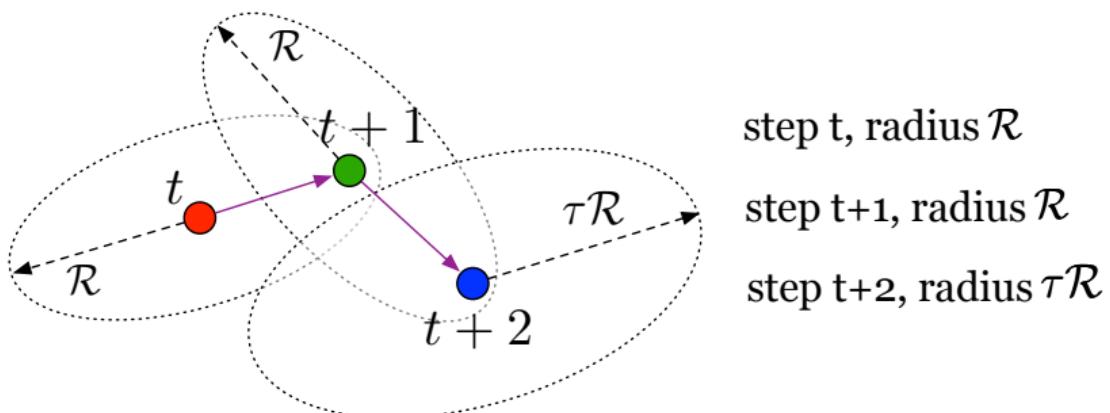
- ▶ Randomly re-sample a batch of sub-sets from the already-sampled configuration set.
- ▶ Build new evaluation functions for each of these re-sampled sub-sets.
- ▶ The final evaluation function is built as the summation of the evaluation functions of these re-sampled sub-sets.



Iterative Opt. – Bootstrap-guided Adaptive Opt. (BAO)

Adaptive Sampling

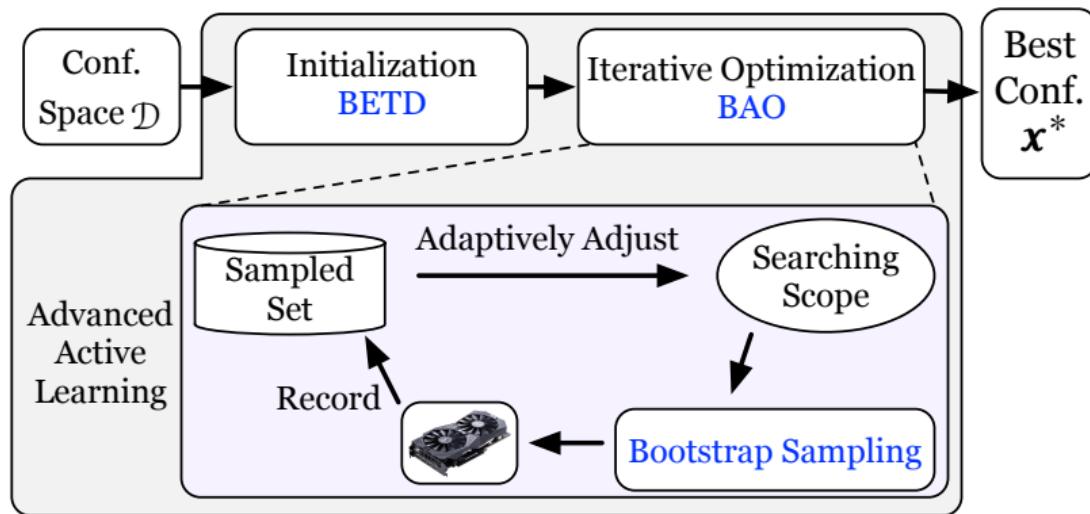
- ▶ Adjust the searching space (neighborhood of the previously-sampled point) adaptively in each optimization step.
- ▶ If the relative performance improvement is satisfying, we will keep the size of the searching space.
- ▶ Otherwise, we will enlarge the searching space.



Our Framework

Advanced active learning

- ▶ Batch transductive experimental design
- ▶ Bootstrap-guided adaptive optimization



Experimental Settings

Platform

- ▶ Intel(R) Xeon(R) E5-2680 v4 CPU@ 2.40GHz
- ▶ NVIDIA GeForce GTX 1080Ti GPU, CUDA 9.0.176

Benchmark

AlexNet, ResNet-18, VGG-16, MobileNet-v1, and SqueezeNet-v1.1

Criterion

- ▶ Inference latency
- ▶ Giga floating operations per second (GFLOPS)

Baseline

- ▶ AutoTVM

Convergence

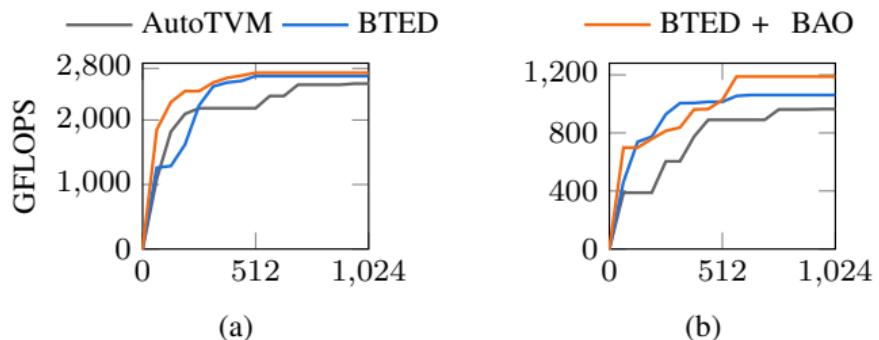


Fig. 4 Convergence trends of GFLOPs for the first 2 layers of MobileNet-v1, (a) the first layer, (b) the second layer.

Sampled Configurations and GFLOPS

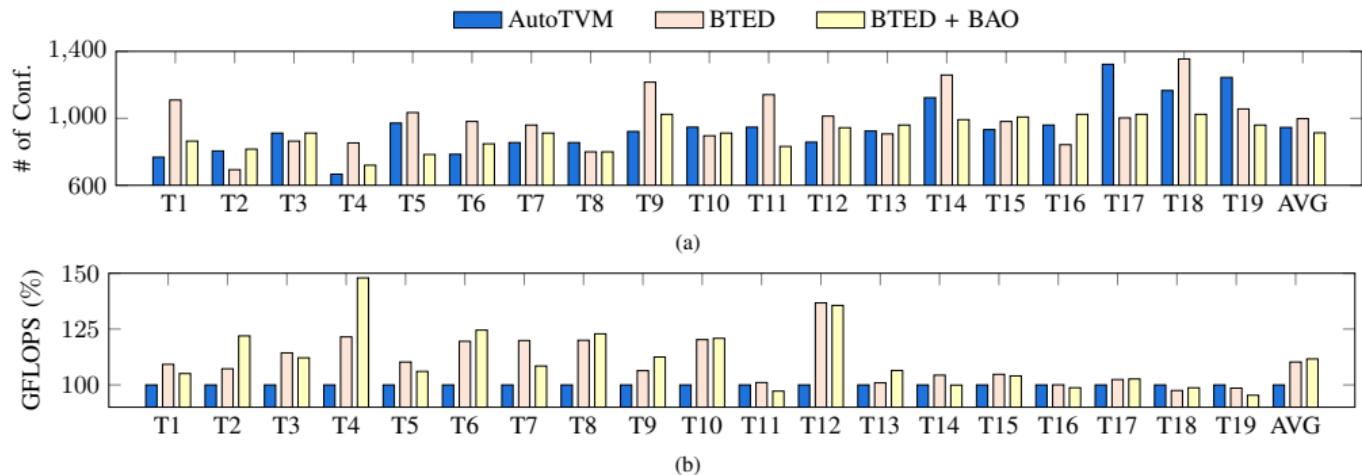


Fig. 5 The number of sampled configurations and GFLOPS values of MobileNet-v1. AVG represents the average results of the 19 tasks.

Results

Table: Comparisons of End-to-end Model Inference Latency and Variance

Model	AutoTVM		BTED				BTED + BAO			
	Latency (ms)	Variance	Latency (ms)	Δ (%)	Variance	Δ (%)	Latency (ms)	Δ (%)	Variance	Δ (%)
AlexNet	1.3639	0.1738	1.3373	- 1.95	0.2246	+29.23	1.3304	- 2.46	0.0711	-59.09
ResNet-18	1.8323	0.4651	1.7935	- 2.12	0.4487	- 3.53	1.7519	- 4.39	0.3848	-17.27
VGG-16	6.5176	2.3834	5.6808	-12.84	0.6574	-72.42	5.6183	-13.80	0.3617	-84.82
MobileNet-v1	1.0597	0.9290	0.8738	-17.54	0.5398	-41.89	0.7621	-28.08	0.0674	-92.74
SqueezeNet-v1.1	0.8697	1.1208	0.7436	-14.50	0.5533	-50.63	0.6920	-20.43	0.1709	-84.75
Average	2.3286	1.0144	2.0858	- 9.79	0.4848	-27.85	2.0309	-13.83	0.2112	-67.74

Thank You